

**Amendments**

Please amend the application as follows:

**In the Specification:**

On page 15, please amend the following paragraph(s) or section(s) starting on line 4 and ending on line 15:

In the one embodiment of FIG. 5A, each of the second and third inputs 224, 226 are servo-motors driving the respective second and third primary joints 214, 216. This configuration provides optimal flexibility of motion and is kinematically simple, such that the drive system 205 is easy to program and control. Alternatively, and as shown in FIG. 5B, each of the robotic arms 202 can be provided with a pulley belt 230 extending from the third primary joint ~~260~~216 within the second primary link 208. With this embodiment, the servo-motors serving as the third inputs 226 are moved inwardly from the third primary joints 216, yet control movement thereof via the respective pulley belts 230. Thus, the potential cantilever concerns presented by a placement of a servo-motor on the third primary links 210 is alleviated. In fact, the servo-motor could be moved to the opposite side of the second primary joint 214 to assist in counter balancing the mass of the respective end effector 211.